

*CLAIM AMENDMENTS*

1. (Currently Amended) A control apparatus for a rotating machine, comprising:  
an integration unit that ~~computes a phase by integrating~~ integrates a primary angular frequency obtained ~~frequency~~ based on an angular velocity command and computes phase;

a power converting unit that applies a three-phase voltage to the rotating machine in accordance with a three-phase voltage command;

a current detecting unit that detects a three-phase current flowing through the rotating machine;

a coordinate converting unit that ~~conducts a coordinate conversion for converting~~ converts coordinates of the three-phase current detected by the current detecting unit into ~~a current components on a rotation-rotating~~ two-axis coordinate coordinates based on the phase ~~output computed~~ by the integration unit, and ~~for converting that converts~~ a voltage command on the ~~rotation-rotating~~ two-axis coordinates into the three-phase voltage command; and

a voltage command computing unit that computes the voltage command on the ~~rotation-rotating~~ two-axis coordinate coordinates, based on the primary angular frequency and deviations in absolute values of ~~each axis component of the current on components~~ along each axis of the rotation-rotating two-axis coordinate coordinates.

2. (Currently Amended) The control apparatus according to claim 1, wherein the voltage command computing unit computes an excitation current command that is changed depending on a load, ~~obtains~~ produces a minor excitation current command by dividing the absolute values of the ~~respective axis~~ current components on the rotation two-axis coordinate by the excitation current command, and computes the voltage commands based on the rotation two-axis coordinate ~~based on the~~ minor excitation current command ~~obtained~~ and the primary angular frequency.

3. (Currently Amended) The control apparatus according to claim 1, further comprising a frequency correcting unit that computes a frequency correction ~~amount~~ based on the current components on the rotation-rotating two-axis coordinate coordinates, and that subtracts the frequency correction ~~amount~~ from the primary angular frequency ~~applied based on the angular velocity command~~, and that outputs ~~the~~ a corrected primary angular frequency from which the frequency correction ~~amount is~~ has been subtracted.